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What is claimed is:

1. (original) A drive device of a printing press, having at least one virtual leading axle (a; b) for presetting a desired angular position (Φ_l') of a drive (08) of at least one unit (01; 02; 03; 04; 06; 07) driven by its own drive motor (M), wherein the leading axle (a; b) is connected to at least one circuit (15; 20), which is able to convert the chronologically changing datum for the angular position of a leading axle position (Φ) into a pulse train ($I(t)$; $I_0(t)$) in the form of output signals ($I(t)$; $I_0(t)$) and it is possible to parameterize the circuit (15; 20) with regard to the number of pulses per rotation ($n/2\pi$).

2. (original) The drive device as recited in claim 1, wherein the pulse train ($I(t)$; $I_0(t)$) is supplied to a drive of a subassembly (19), which is independently driven by the drive (08) of the unit (01; 02; 03; 04; 06; 07) that is coupled to the leading axle (a; b).

3. (original) The drive device as recited in claim 1, wherein the circuit includes a number of subcircuits that are able to generate a number of pulse trains ($I(t)$) in the form of output signals ($I(t)$) at a number of outputs.

4. (currently amended) The drive device as recited in claim 1 ~~or 3~~, wherein the circuit (15; 20) or subcircuit is adjustable with regard to additional parameters ($n/2\pi$, τ, I, $I_n(t)$, "0") that relate to the shape of the output signal ($I(t)$).

5. (currently amended) The drive device as recited in claim 1 ~~or 3~~, wherein the circuit (15; 20) or subcircuit is embodied in the form of an emulator circuit.

6. (currently amended) The drive device as recited in claim 1 ~~or 3~~,

wherein the input of the circuit (15; 20) or subcircuit receives the current leading axle position (Φ) from a drive control unit (13) or a computing and data processing unit (11) of the printing press.

7. (original) The drive device as recited in claim 1,
wherein the circuit (15; 20) is connected as a client to a network (09) that conveys the leading axle position (Φ) and receives its angular position at its input.

8. (original) The drive device as recited in claim 1,
wherein a drive control unit (13) that presets the leading axle position (Φ) is provided, which has at least one circuit (15; 20).

9. (original) The drive device as recited in claim 1,
wherein a first and at least one second circuit (20; 15) are provided for conversion purposes.

10. (original) The drive device as recited in claim 9,
wherein a drive control unit (13; 17) that presets the leading axle position (Φ) has a first circuit (20), which converts the chronologically changing datum of the leading axle position (Φ) into a first pulse train ($I_0(t)$) with a fixed, definite number of pulses per rotation ($n/2\pi$) of the leading axle (a; b).

11. (original) The drive device as recited in claim 10,
wherein an output of the first circuit (20) communicates with the input of a second circuit (15), which is able to convert the first pulse train ($I_0(t)$) into a new pulse-shaped output signal ($I(t)$) in conjunction with parameters ($n/2\pi$, τ, I, $I_n(t)$, "0") that influence the shape.

12. (currently amended) The drive device as recited in claim 3 ~~and 11~~,

wherein the second circuit (15) has a number of subcircuits, which are able to generate a number of different pulse trains (I(t)) in the form of output signals (I(t)) at a number of outputs.

13. (currently amended) The drive device as recited in claim 11 ~~or 12~~, wherein the parameters ($n/2\pi$, τ, I, $I_n(t)$, "0") of the circuit (15) or its subcircuits are adjustable.

14. (currently amended) The drive device as recited in claim 1 ~~or 13~~, wherein it is possible to parameterize the output signal (I(t)) with regard to the number of output pulses per rotation ($n/2\pi$) of the leading axle (a; b).

15. (currently amended) The drive device as recited in claim 1 ~~or 13~~, wherein it is possible to parameterize the circuit (15; 20) with regard to the number of pulses per rotation ($n/2\pi$) of a subassembly (19) to be controlled by means of the circuit (15; 20).

16. (currently amended) The drive device as recited in claim 4 ~~or 13~~, wherein it is possible to parameterize the output signal (I(t)) with regard to a height of its amplitude (I).

17. (currently amended) The drive device as recited in claim 1, ~~3, 11, or 12~~, wherein the converted pulse train (I(t)) is present at the output of the circuit (15; 20) in the form of a digital output signal (I(t)).

18. (currently amended) The drive device as recited in claim 1, ~~3, 11, or 12~~, wherein the converted pulse train (I(t)) is present at the output of the circuit (15; 20) in the form of an analog output signal (I(t)).

19. (currently amended) The drive device as recited in claim 1, ~~3, 11, or 12~~,

wherein the output signal ($I(t)$) at an output has a set of correlated pulse trains ($I_A(t)$; $I_B(t)$; $I_C(t)$).

20. (currently amended) The drive device as recited in claim 4 ~~or 13~~, wherein the circuit (15; 20) is detachably connected to a computing unit (11) in order to adjust the parameters ($n/2\pi$, τ, I, $I_n(t)$, "0").

21. (original) The drive device as recited in claim 1, wherein the leading axle position (Φ) is preset by a drive control unit (13; 17).

22. (currently amended) The drive device as recited in claim 10 ~~or 21~~, wherein the drive control unit (13; 17) that presets the leading axle position (Φ) is embodied in the form of an independent master for all of the drives (08) that are coupled to this leading axle (a; b).

23. (currently amended) The drive device as recited in claim 10 ~~or 21~~, wherein the drive control unit (17) that presets the leading axle position (Φ) is embodied as a drive control unit (17) of a folding unit (06).

24. (original) A method for controlling a subassembly of a printing press having at least one virtual leading axle (a; b) for presetting a desired angular position (Φ_i') of a drive (08) of at least one unit (01; 02; 03; 04; 06; 07) driven by its own drive motor (M),

wherein at least one circuit (15; 20) connected to the leading axle (a; b) converts the chronologically changing datum for the angular position of a leading axle position (Φ) into a pulse train ($I(t)$; $I_0(t)$) and supplies it in the form of output signals ($I(t)$; $I_0(t)$) to the subassembly (19) and an incremental resolution between the rotating leading axle (a; b) and an angular position transducer of a subassembly (19) to be controlled via the circuit (15; 20) and/or its drive motor is performed by parameterizing the circuit.